

Remeshing free, graph-based FEM allows us to scale fracture simulations to very high resolution volumetric meshes at speeds faster than any other method present in literature.

Scalable Visual Simulation Of Brittle And Ductile Fracture

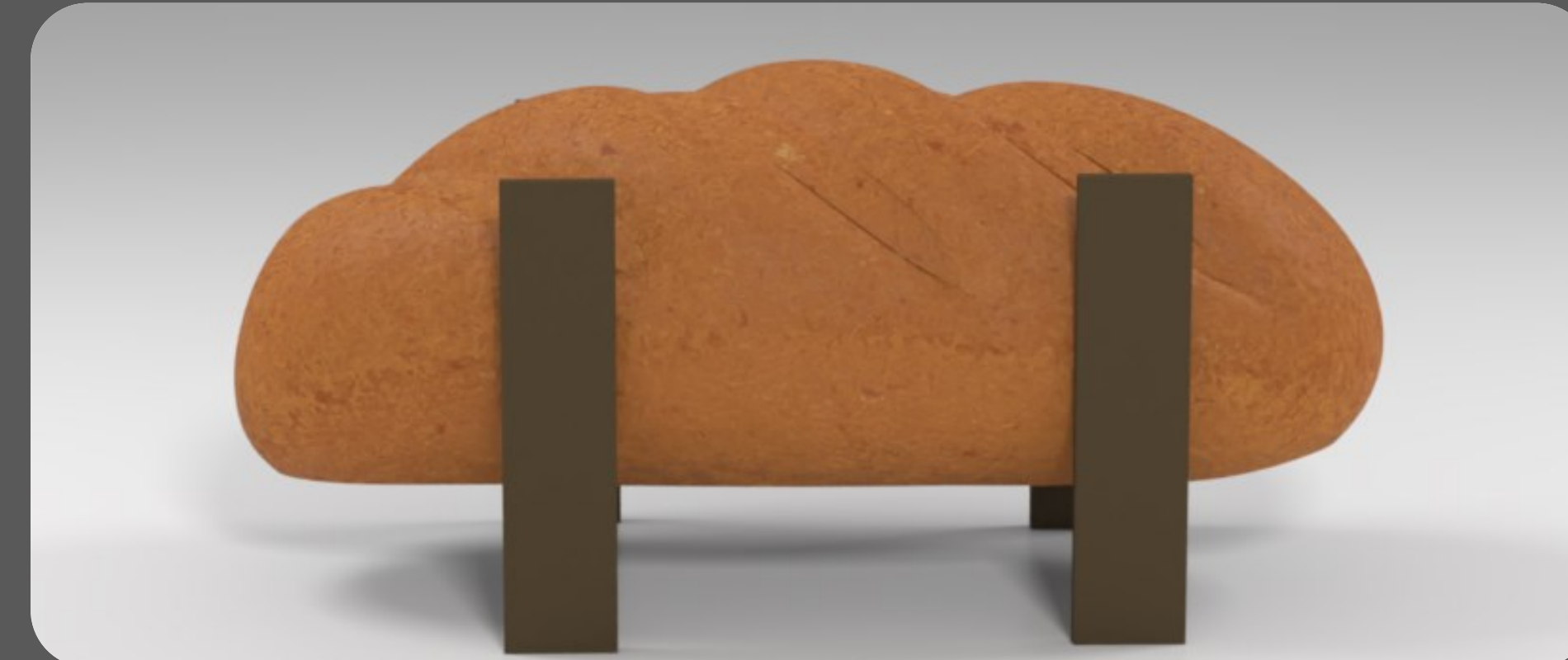
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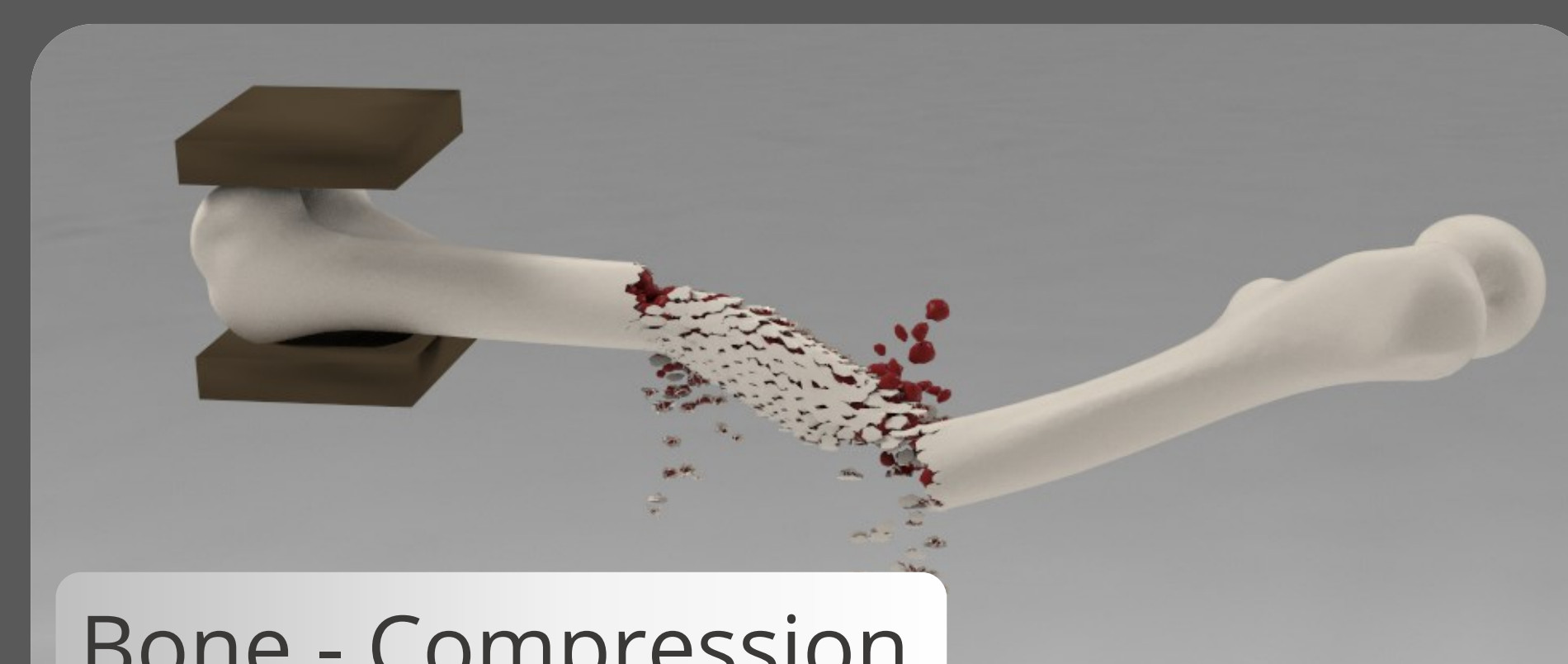
Results



Blue Jade Armadillo



Loaf of Bread



Bone - Compression



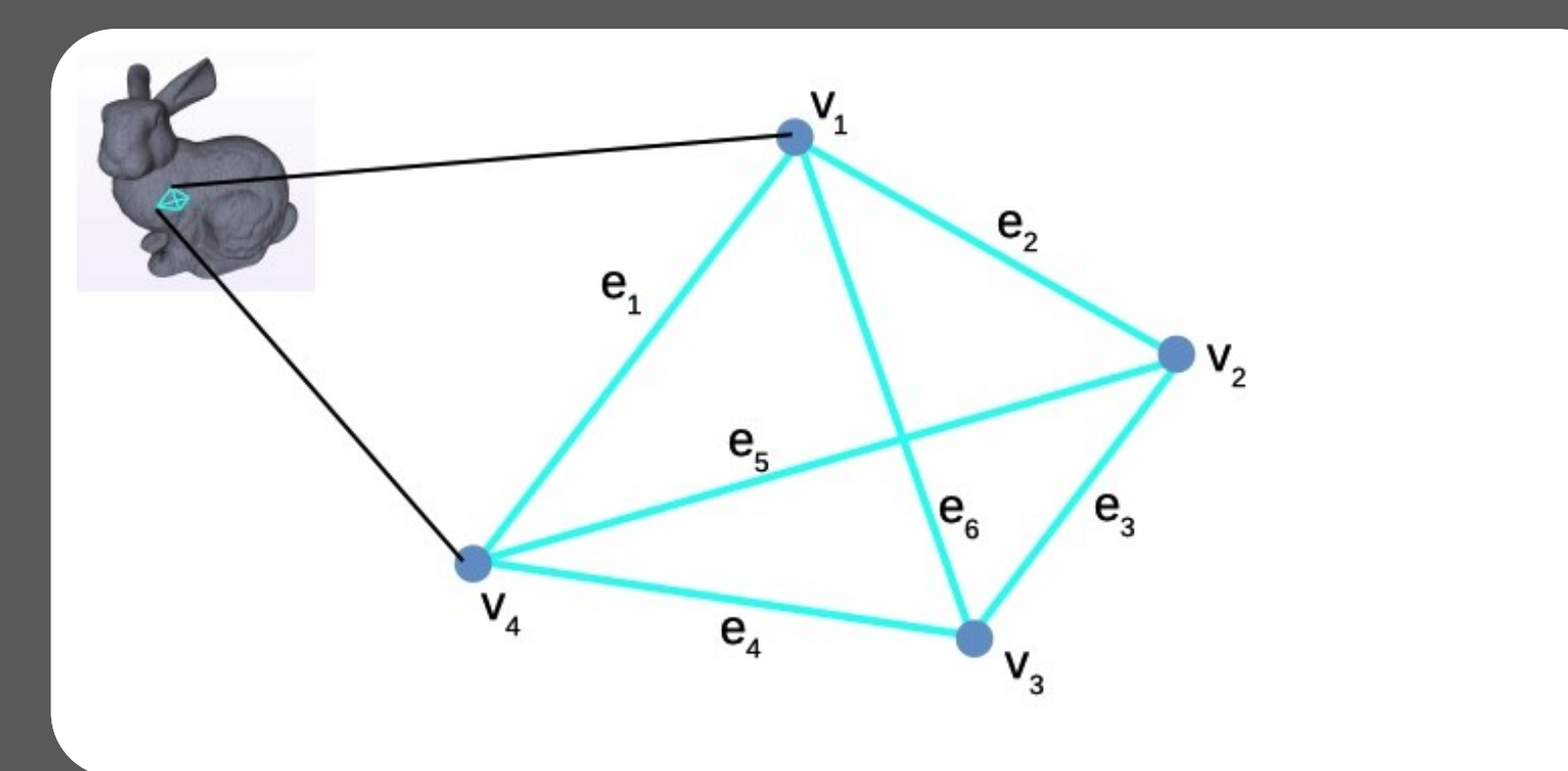
Bone - Shear

Motivation

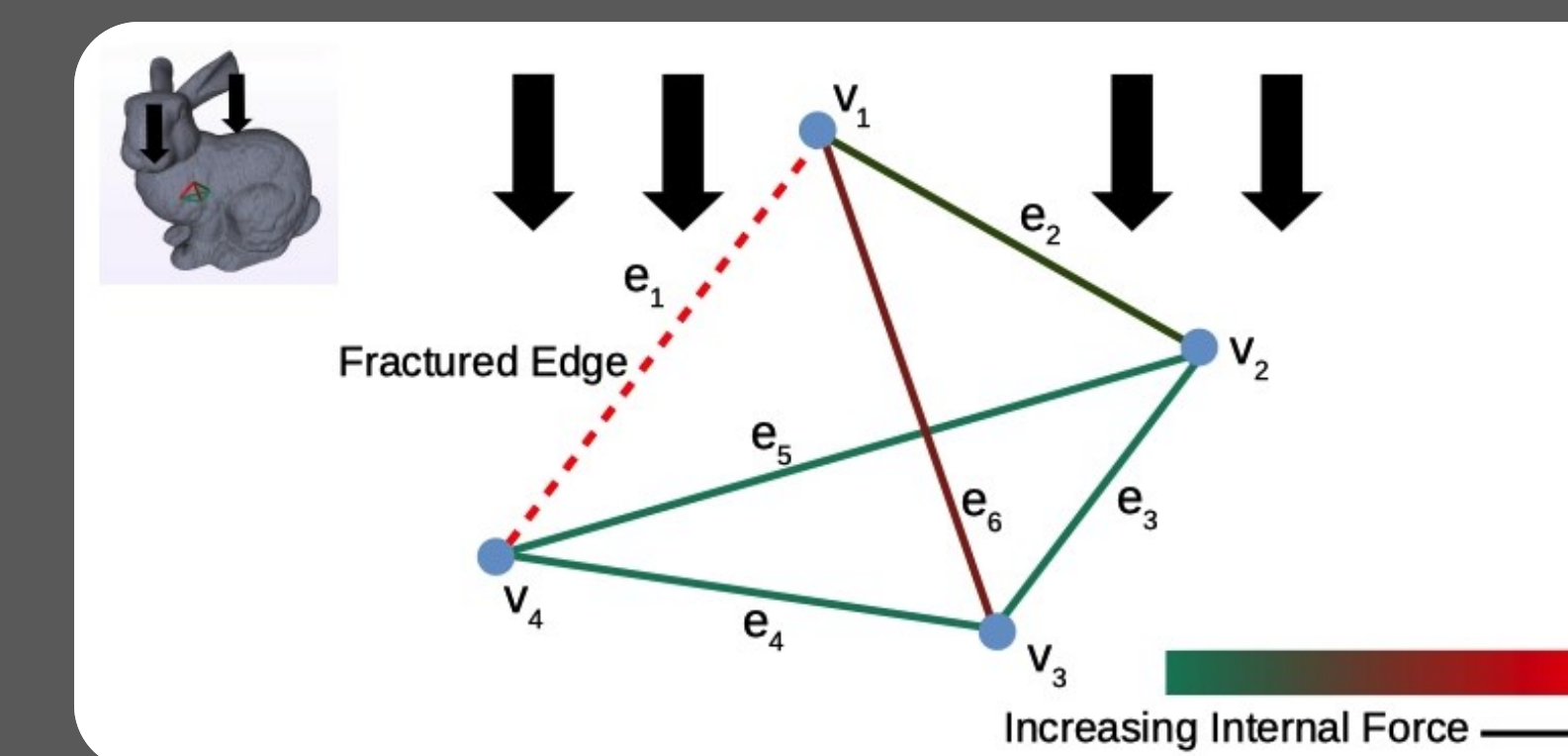
- FEM system matrix scales rapidly with increase in number of fracture fragments due to re-meshing [1].
- Other limitations in some methods include high computation cost [3] and presence of degenerate elements.

Solution

- Graph-based FEM [2] works on graph induced in a volumetric mesh.



- Hyper-elastic strain energy can be reformulated in terms of only edge lengths.
- Relabel the edges using a damage variable to mark them as fractured.



References

- Chitalu et al., Displacement Correlated XFEM for Simulating Brittle Fracture, *Comp. Graph. Forum*, 39:2 (2020), 569-583.
- Khodabakshi et al., GraFEA: a graph-based finite element approach for study of damage and fracture in brittle materials, *Meccanica*, 51 (2016), 3129-3147.
- Levine et al., A Peridynamic Perspective on Spring-Mass Fracture, *In Proc. Of SCA'14*, 47-55.

Visualization

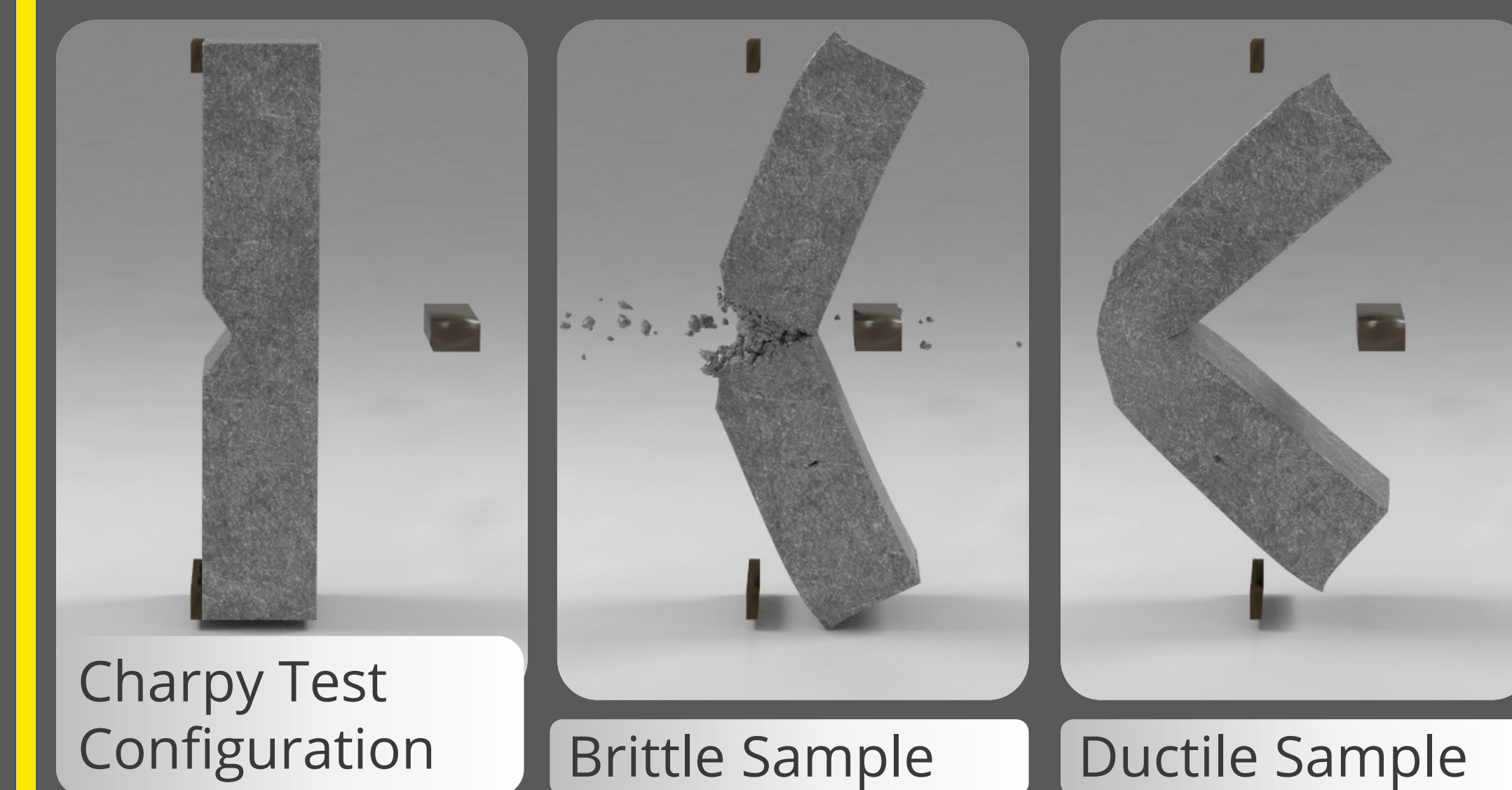
- The computational volumetric mesh never needs to be remeshed, so the size of the system matrix never increases.
- The visualization surface mesh is remeshed, for rendering.

Algorithm

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Algorithm 1: Remeshing-Free Graph-based Fracture
Initialize FEM simulation;
while True do
  for each element in  $\mathcal{M}_c$  do
    Calculate stress along the edges  $\sigma_{mn}$ ;
    if  $\sigma_{mn} > \sigma_{thres}$  then
      Label the edge as damaged;
      Remesh the surface of the corresponding  $\mathcal{M}_v$ ;
    end
  Resolve all collisions with  $\mathcal{M}_c$ ;
  Calculate impulse force due to collision;
  Add all external forces to the vertices of  $\mathcal{M}_c$ ;
end
Build full system  $[M]_{n_v \times n_v} [v]_{n_v \times 1} = [f]_{n_v \times 1}$ ;
Solve for velocity vector  $[v]_{n_v \times 1}$ ;
for each vertex in  $\mathcal{M}_c$  and  $\mathcal{M}_v$  do
  Update position vector by  $[x]_{n_v \times 1} + \Delta t \cdot [v]_{n_v \times 1}$ ;
end
end
  
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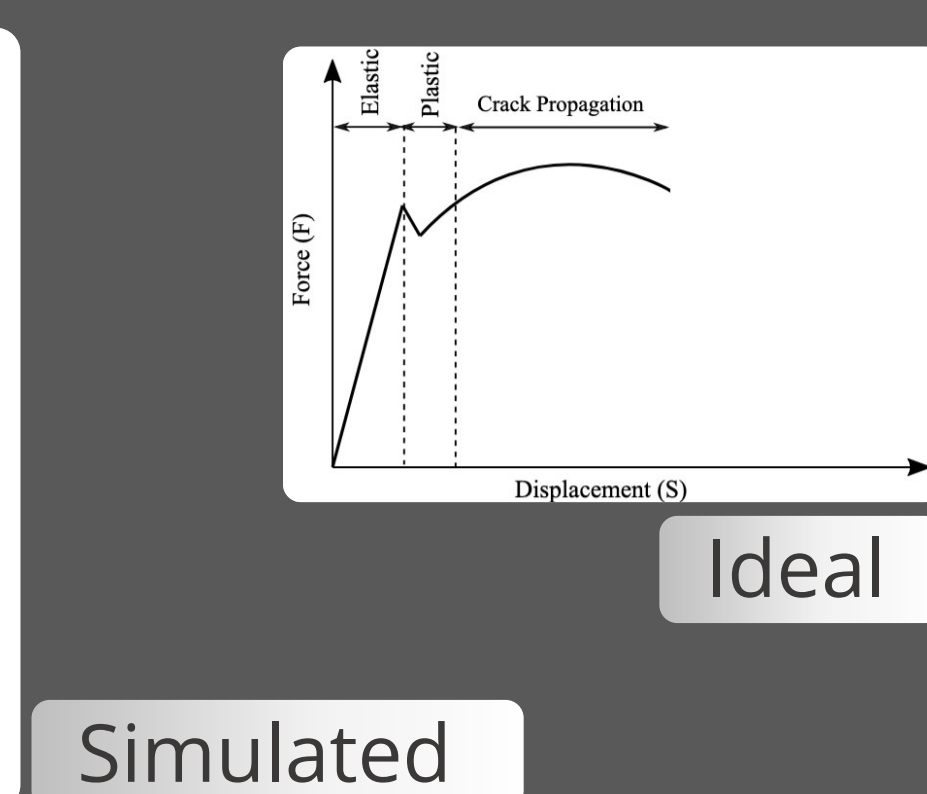
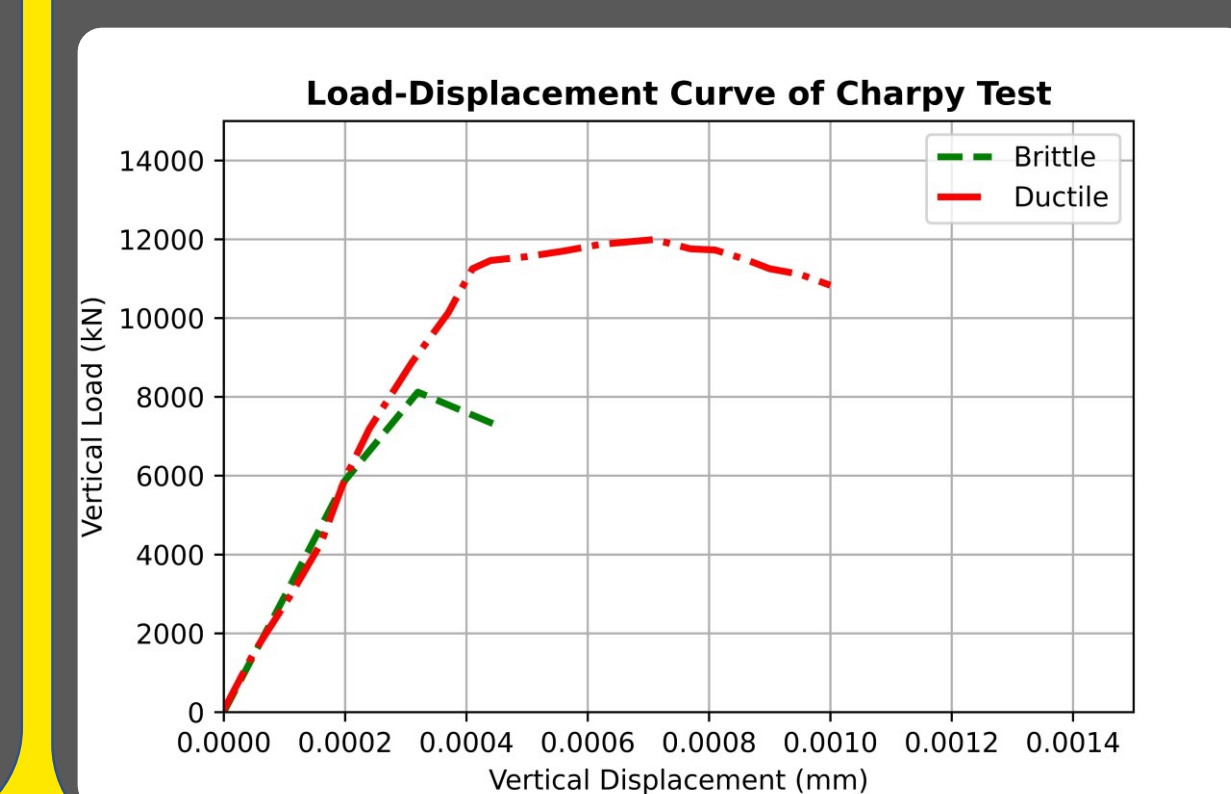
Validation



Charpy Test Configuration

Brittle Sample

Ductile Sample



Simulated

Full Paper Link
<http://arxiv.org/abs/2103.14870>



IIT Bombay



SIGGRAPH 2021



Video Link